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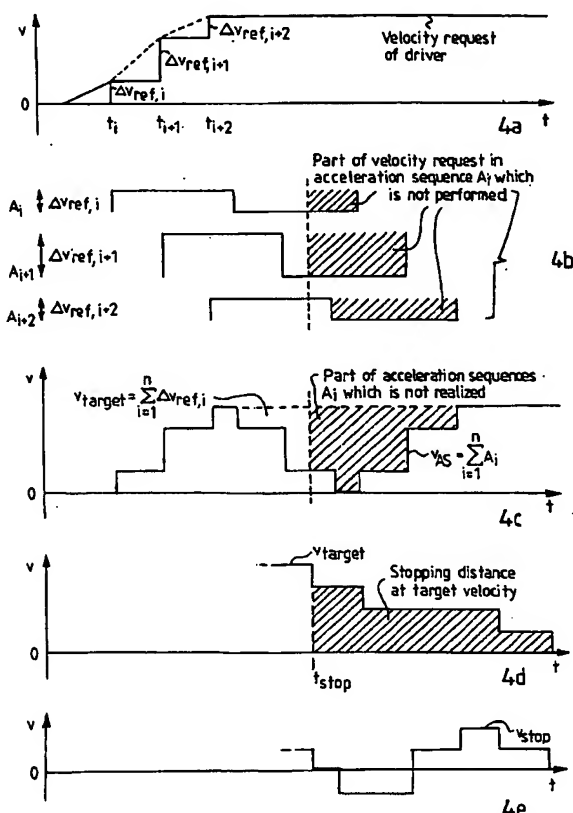
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(54) Title: METHOD FOR CONTROLLING A CRANE



(57) Abstract: The invention relates to a method for controlling a crane, the method comprising defining, at each time, the distance (s) the crane moves before stopping and without swinging of the load fastened to it by summing up a stopping distance (s_1), which is calculated on the basis of the internal target velocity, i.e. the velocity which the control of the algorithm implementing this has after the stored velocity changes are entirely implemented, by using the selected deceleration ramp; and a distance (s_2), which is calculated on the basis of stored velocity change requests stated before the stopping decision and on the basis of remaining performance times.



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